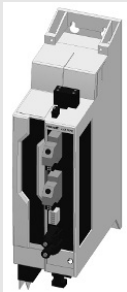


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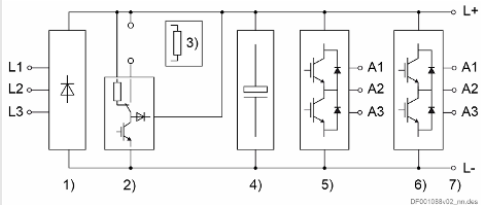
- Double-axis converter XCD

Double-axis converter XCD

Double-axis converter XCD



Double-axis converter



1) Mains input with rectifier
 2) Integrated braking transistor/braking resistor
 3) Optional external braking resistor
 4) DC bus capacitors
 5) Inverter stage axis 1 with output to motor
 6) Inverter stage axis 2 with output to motor
 7) DC bus connection

XCD type code

Short type designation	1	2	3	4	5	6	7	8	9	1	1	2	3	4	5	6	7	8	9	2	1	2	3	4	5	6	7	8	9	3	1	2	3	4	5	6	7	8	9	4
										0										0										0										0
Example:	X	C	D	2	-	W	2	3	2	3	A	R	N	-	0	1	N	E	T	T	0	E	C	N	N	-	S	0	3	R	S	N	1	N	N	N	P	0	N	N
	①					②	③				④	⑤	⑥		⑦		⑧	⑨		⑩		⑪		⑫			⑬	⑭		⑮		⑯	⑰	⑱			⑲	⑳	㉑	
①	Product: 1: X = ctrlX DRIVE 2: C = Feeding converter 3: D = Double-axis 4: 2 = Generation 2; 1 = Generation 1																																							
②	Cooling type: W = Air, internal																																							
③	Maximum current: 2323 = 23A/23A (example) Maximum currents: 2323																																							
④	Degree of protection, input voltage: A = IP20, 3 × AC 200 ... 500 V +10% -15%																																							
⑤	Other power section options: R = Integrated braking transistor/braking resistor																																							
⑥	Connector set: N = Without motor connector set																																							
⑦	Control section: 01 = ctrlX DRIVE 02 = ctrlX DRIVE ^{plus}																																							

Short type designation	1	2	3	4	5	6	7	8	9	1	2	3	4	5	6	7	8	9	2	1	2	3	4	5	6	7	8	9	3	1	2	3	4	5	6	7	8	9	4	
										0									0										0										0	
Example:	X	C	D	2	-	W	2	3	2	3	A	R	N	-	0	1	N	E	T	T	0	E	C	N	N	-	S	0	3	R	S	N	1	N	N	N	P	0	N	N
	①					②	③				④	⑤	⑥				⑦	⑧	⑨	⑩		⑪		⑫			⑬	⑭	⑮		⑯	⑰	⑱				⑲	⑳	㉑	
⑧	Panel: N = Without panel A = With panel																																							
⑨	Communication: ET = Multi-Ethernet EX = Multi-Ethernet incl. ctrlX OS X3 = ctrlX CORE																																							
⑩	Hardware option 1 - Safety: T0 = Safe Torque Off (STO) M5 = SafeMotion (M5) M8 = SafeMotion (M8)																																							
⑪	Hardware option 2: EC = Multi-encoder interface NN = Not equipped																																							
⑫	Hardware option 3: ET = Multi-Ethernet NN = Not equipped																																							
⑬	Runtime type: S = Standard																																							
⑭	Runtime version: 02 = Version 02 (XCD1) 03 = Version 03 (XCD2) 04 = Version 04 (XCD2) 05 = Version 05 (XCD2)																																							
⑮	Runtime release: RS = Standard (current release)																																							
⑯	Export licenses required: N = No (maximum output frequency < 599 Hz) E = Restricted export (maximum output frequency > 599 Hz)																																							
⑰	Protocol - communication: 0 = Defined via ctrlX CORE Apps (XCD2) 1 = Sercos III 2 = EtherCAT (SoE) 3 = EtherCAT (CoE) 4 = PROFINET IO																																							
⑱	Technology Function: NNN = None TF1 = Uploading Technology Apps (XCD2) TE1 = Uploading/programming Technology Apps (XCD2) TX1 = Uploading/programming Technology Apps incl. LIBs (Bosch Rexroth libraries) (XCD2)																																							

Short type designation	1	2	3	4	5	6	7	8	9	1	1	2	3	4	5	6	7	8	9	2	1	2	3	4	5	6	7	8	9	3	1	2	3	4	5	6	7	8	9	4
									0										0										0									0		
Example:	X	C	D	2	-	W	2	3	2	3	A	R	N	-	0	1	N	E	T	T	0	E	C	N	N	-	S	0	3	R	S	N	1	N	N	N	P	0	N	N
	①					②	③				④	⑤	⑥		⑦		⑧	⑨		⑩		⑪		⑫			⑬	⑭		⑮		⑯	⑰	⑱		⑲	⑳	㉑		
⑲	Scope of functions, Runtime: N = DRIVE Runtime P = DRIVE Runtime Productivity																																							
⑳	Scope of functions, SafeMotion: 0 = Option 1 ≠ SafeMotion 3 = SafeMotion Speed 5 = SafeMotion Position																																							
㉑	Other design: NN = None																																							